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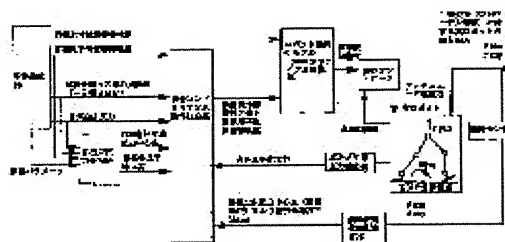
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MATSUMOTO TAKASHI**(54) CONTROLLER FOR LEG-TYPE MOBILE ROBOT**

(57)Abstract:

**PROBLEM TO BE SOLVED:** To easily and properly control an actual reactive force applied on a robot without any interference by providing a leg part rotational amount deciding means or the like.

**SOLUTION:** The coordinate of a first target sole floor reactive force center point and the coordinate of a second target sole floor reactive force center point are rotated and moved around a normal vector by amounts equal to a rotational angle  $\theta$  (both-leg compensating angle) with respective target full-floor reactive force center points set as rotational centers. In this case, by simultaneously operating both-leg compensating angle, each sole X compensating angle and each sole Y compensating angle, the changing amount of each actual sole floor reactive force is a sum of a changing amount when each is singly operated. Accordingly, these operations have linear characteristics. Thus, each actual sole floor reactive force moment is calculated in the moving target sole floor reactive force center point and, based on each, a sole is rotated around the sole floor reactive force center point, and a moment around the point is controlled to a desired value. Thus, control is facilitated without any interference between actual full-floor reactive force and each sole floor reactive force.

**LEGAL STATUS**

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